

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for advancing and retreating linearly <sup>in a direction</sup> and radially relative to said central axis,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the work, and  
outer surfaces of said chuck fingers being tapered at least at tip end portions thereof,  
tapering inward toward said central axis approaching the tips, for contact with an inlet of the  
insertion hole;

BC hole position detecting means for detecting the position of the insertion hole, said hole  
position detection means comprising a force sensor for detecting the magnitude and direction of a  
resultant force of reaction forces which said piston chuck fingers receive from the cylinder bore  
upon contact therewith.--

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#### REMARKS

A "Substitute Specification and Abstract" is submitted herewith to place the application in better English form. The "Substitute Specification and Abstract" contains no new matter. So that the examiner may satisfy himself in this regard, also submitted herewith is a marked-up copy of the original specification and abstract from which the "Substitute Specification and Abstract" was typed.

Regarding the additional recitation of a "drive means" in claim 1 and new claim 17, the examiner's attention is directed to the first full paragraph at page 20 of applicants' original

specification. The examiner will note that the drive means for moving the chuck fingers radially, inwardly and outwardly, includes a motor shown as "66" in Fig. 2 of the drawings.

What is known in the art as "vacuum chucking" is perhaps best described in applicants' specification at page 14, line 16 to page 15, line 4. See, for example, claim 15.

The linear and radial motion of the chuck finger 65 (radial sliding motion) is perhaps best described at page 20, lines 13-21 of applicants' specification. Note the radially extending keyed grooves in the circular plate in which fingers 65 are mounted, as seen in the drawing figures.

The hole position detecting by a force sensor 69 is described in applicants' original specification beginning at page 21, line 5 and serves to support the language of newly added claim 25.

The allowance of claims 11-15 is noted with appreciation. Further, the allowability of claim 6 has been noted and claim 2 has been amended to incorporate language corresponding to the limitation of original claim 6 and, therefore, is also believed to be in condition for allowance. Note that the same limitation is also found in newly added claims 19 and 21-23.

The restriction requirement is now moot in view of cancellation of non-elected claim 16.

Responsive to paragraph 6 of the office action claim 8 has been amended as requested by

the examiner. Moreover, claim 8 and most of the other pending claims have been amended to place them in somewhat better form.

Responsive to paragraphs 7 and 8 of the office action, claim 6 has been cancelled and the rejection is therefore considered moot. However, as will be elaborated upon below, the limitation of claim 6, as now found in independent claims 2, 11, 13, 19 and 21, has been worded in a manner to cure the problem with antecedent basis noted by the examiner.

The rejection of claims 1, 3-5, 7 and 10 for anticipation by Hill is respectfully traversed. The arms 11 of Hill do not move radially in a linear line relative to any central axis. Stated differently, they are not mounted for sliding movement relative to a central axis. On the contrary, the arms 11 of Hill pivot “at their upper ends in suitable recesses 12 provided in the arms of spider 5,” quoting from lines 78-81 at page 1 of Hill.

Claims 3-5 are considered to be further distinguished from Hill in that, in addition to recitation of the drive means for the aforementioned radial sliding movement, these claims also recite hole positioning fingers in addition to the chuck fingers. Also note that claim 4 requires that the hole positioning detecting fingers be pivotally connected to tip end portions of the chuck fingers and that claim 5 calls for a base portion which both supports the chuck fingers for radial movement and the hole positioning fingers for pivotal movement.

With regard to claim 10, the arms 11 of Hill would not be capable of chucking both a piston and a connecting rod simultaneously.

With regard to claim 7, note that claim 7, claim 11 (and claims 12, 14 and 15 dependent thereon) and claim 13, in the discussion of Figs. 9 and 10 at pages 32 and 33 of applicants' original specification, teaches that the pushing mechanism includes a cylinder 73 and a plunger 74. Gravity is not the mechanical equivalent of such a piston mechanism. Gravity definitely will not serve to insert a piston assembly into a horizontally oriented cylinder as shown, for example, in Fig. 1 of applicants' drawings.

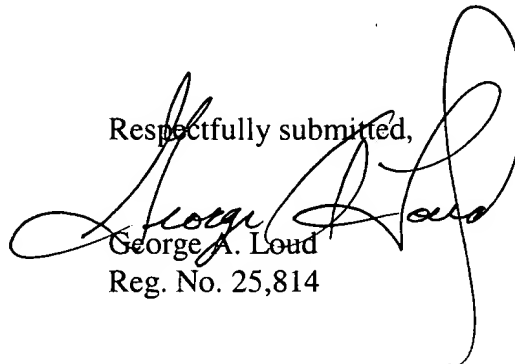
The rejection of claim 2 over Inoyama et al is also traversed. As in Hill, the chucking arms of Inoyama et al grasp a work through pivotal motion rather than by sliding (linear) radial motion. In this regard, also note the wording of independent claims 1, 3 and 20.

Further, the rejection of claim 2 is believed to be moot in any event because of incorporation of the limitation of cancelled claim 6.

Finally, the rejection of claim 8 over Hill in view of Yokomachi et al is respectfully traversed. Claim 8 depends from claim 1 and requires the mounting of the chuck fingers for linear and radial motion relative to a central axis, a feature found neither in Hill nor in Yokomachi et al.

In conclusion, it is respectfully requested that the examiner reconsider the rejections of record with a view toward allowance of the claims as amended.

Respectfully submitted,

A large, stylized handwritten signature in black ink, likely belonging to George A. Loud, is written over the typed name and registration number.

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1. (Amended) A work chucking/inserting apparatus [to be used] for chucking a work, for aligning the work with an insertion hole and for inserting the work into the [an] insertion hole [in alignment with the hole], said apparatus comprising [including]:

three or more chuck fingers,

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for [capable of] advancing and retreating linearly and radially relative to said central axis,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the [said] work, and

outer surfaces of said chuck fingers being tapered at least at tip end portions thereof, tapering inward toward said central axis approaching [so that the closer to] the tips, for [the more inwards the taper, and capable of coming into] contact with an inlet of the [said] insertion hole; and

drive means for advancing and retracting said chuck fingers linearly and radially relative to said central axis.

2. (Amended) A work chucking/inserting apparatus [to be used] for chucking a work, for aligning the work with an insertion hole and for inserting the work into the [an] insertion hole [in alignment with the hole], said apparatus comprising [including]:

three or more chuck fingers,

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for [capable of] advancing and retreating linearly and radially relative

to said central axis,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the [said] work, and

outer surfaces of said chuck fingers having at least at tip end portions thereof surfaces extending parallel to said central axis for [an inner peripheral surface of said insertion hole, and capable of being brought into] contact with an inlet of the [said] insertion hole; and

tracer means for, when the outer surfaces of said chuck fingers come into contact with the inlet of the insertion hole, reorienting said apparatus to bring said central axis into alignment with a central axis of the insertion hole.

3. (Amended) A work chucking/inserting apparatus [to be used] for chucking a work, for aligning the work with an insertion hole and inserting the work into the [an] insertion hole [in alignment with the hole], said apparatus comprising [including]:

three or more chuck fingers and three or more hole position detecting fingers,

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for [capable of] advancing and retreating linearly and radially relative to said central axis,

said hole position detecting fingers being arranged in circumferentially spaced positions and pivotable inwards and outwards relative to said central axis, about pivot points [, centered] on base end portions thereof,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the [said] work, and

outer surfaces of said hole position detecting fingers being tapered at least at tip end portions thereof, tapering inward toward said central axis approaching [so that the closer to] the tips, for [the more inwards the taper, and capable of coming into] contact with an inlet of the [said] insertion hole; and

drive means for advancing and retracting said chuck fingers linearly and radially relative to said central axis.

5. (Amended) A work chucking/inserting apparatus according to claim 3, wherein the base end portions of said hole position detecting fingers are pivotally connected to a base portion, said base portion supporting [by which base portions of] said chuck fingers [are supported] for radial advance and retreat.

8. (Twice Amended) A work chucking/inserting apparatus according to claim 1, wherein the inlet of the [said] insertion hole is chamfered, and the tip end portions of said chuck fingers are respectively formed with projections which mate with [can fill up] the chamfered portion when the [said] work is inserted into the [said] insertion hole.

9. (Twice Amended) A work chucking/inserting apparatus according to claim 1, wherein the [said] work is a piston or an assembly of a piston and a connecting rod, and the [said] insertion hole is a cylinder bore.

10. (Amended) A work chucking/inserting apparatus according to claim 3, wherein the [said]

work is an assembly of a piston and a connecting rod, the [said] insertion hole is a cylinder bore, said chuck fingers chuck said piston, and said hole position detecting fingers also serve as means for chucking said connecting rod.

11. (Amended) A work chucking/inserting apparatus [to be used] for chucking a work, for aligning the work with an insertion hole and for inserting the work into the [an] insertion hole [in alignment with the hole], said apparatus comprising [including]:

three or more chuck fingers,

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for [capable of] advancing and retreating linearly and radially relative to said central axis,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the [said] work and each having a portion tapering inward toward said central axis approaching a distal end [tapered such that the closer to the tip] thereof, [the more inwards the taper,]

outer surfaces of said chuck fingers being tapered at least at tip end portions thereof, tapering inward toward said central axis approaching [so that the closer to] the tips, for [the more inwards the taper, and capable of coming into] contact with an inlet of the [said] insertion hole,

tracer means for, when the outer surfaces of said chuck fingers come into contact with the inlet of the insertion hole, reorienting said apparatus to bring said central axis into alignment with a central axis of the insertion hole, and

[a tracer mechanism for causing the axis of a conical surface defined by the outer surfaces of said three or more chuck fingers to be aligned with the axis of said insertion hole when said

outer surfaces come into contact with the inlet of said insertion hole, and]

[a] pushing means [mechanism] for pushing the work toward the [said] insertion hole.

12. (Amended) A work chucking/inserting apparatus according to claim 11, wherein the inlet of the [said] insertion hole is chamfered, and the tips of the outer surfaces of said chuck fingers are shaped to mate with [formed so that they can come into abutment against] the chamfered portion when the [said] work is inserted into the [said] insertion hole.

13. (Amended) A work chucking/inserting apparatus [to be used] for chucking a work, for aligning the work with an insertion hole and for inserting the work into the [an] insertion hole, the insertion hole having a chamfered inlet, said apparatus comprising [in alignment with the hole, including]:

three or more chuck fingers,

said chuck fingers being arranged in circumferentially spaced positions around a central axis and slidably mounted for [capable of] advancing and retreating radially,

inner surfaces of said chuck fingers serving as chuck surfaces for chucking the [said] work and each having a portion tapering inward toward said central axis approaching a distal end [tapered such that the closer to the tip] thereof, [the more inwards the taper,]

end faces of said distal ends of said chuck fingers being at least partially flat for [at their portions except their portions close to their inner peripheral edges, and capable of] coming into abutment against a wall surface which surrounds an inlet of the [said] insertion hole,

outer surfaces of said chuck fingers having at least at tip end portions thereof surfaces

extending parallel to said central axis for contact with an inlet of the insertion hole,

[the portions close to said inner peripheral edges being tapered such that the closer to the tips, the more inwards the taper, and capable of coming into contact with the inlet of said insertion hole,

the inlet of said insertion hole being chamfered,

the] portions close to [the] inner peripheral edges of the end faces of said chuck fingers mating with [being capable of coming into abutment against] the chamfered portion of the inlet of said insertion hole when said work is inserted into said insertion hole,

tracer means for, when the outer surfaces of said chuck fingers come into contact with the inlet of the insertion hole, reorienting said apparatus to bring said central axis into alignment with a central axis of the insertion hole, and

[a tracer mechanism for causing the axis of a conical surface defined by the portions close to the inner peripheral edges of the end faces of said three or more chuck fingers to become aligned with the axis of said insertion hole when the portions close to said inner peripheral edges come into contact with the inlet of said insertion hole, and]

[a] pushing means [mechanism] for pushing said work toward the [said] insertion hole.

14. (Twice Amended) A work chucking/inserting apparatus according to claim 11, wherein the [said] work is a piston or an assembly of a piston and a connecting rod, and the [said] insertion hole is a cylinder bore.

15. (Twice Amended) A work chucking/inserting apparatus according to claim 11, wherein said

pushing means includes a vacuum chuck [mechanism possesses a work sucking function] for  
holding the [sucking said] work.

# WORK CHUCKING/INSERTING APPARATUS AND ASSEMBLING UNIT

## BACKGROUND OF THE INVENTION

### Field of the Invention

The present invention relates to a work chucking/inserting apparatus and more particularly, to a work chucking/inserting apparatus <sup>of simple structure</sup> capable of handling various sizes of works <sup>for alignment with and insertion</sup> in inserting a work into an insertion hole in an aligned state with the insertion hole and capable of <sup>within</sup> attaining the insertion with a simple structure in a short time and <sup>with</sup> in a high working efficiency.

### Description of the Prior Art

In inserting a work into an insertion hole <sup>and fitting them together</sup> with use of <sup>such a machine</sup> as a robot, conventional techniques correct a <sup>positional deviation between the insertion hole and the present position of</sup> [positional] deviation between the insertion hole and the present position of the work by using a jig for insertion or using a Vision (a two-dimensional visual device) to detect the position of the insertion hole.

<sup>Through-hole with</sup> For example, in the case where a jig for insertion is used (Japanese Patent Laid Open No. 115129/84), as shown in Fig. 17, <sup>the</sup> an inserting jig 01 has an inlet <sup>opening</sup> larger than an insertion hole 02. The <sup>portion adjacent to the</sup> [inlet is] tapered or gently curved <sup>inward</sup> and leads to an outlet (insertion port) which is of the same shape as <sup>the opening</sup> an inlet portion of the insertion hole 02 located on the side opposite <sup>opening</sup> to the inlet of the inserting jig 01.

The inserting jig 01 having such a shape is first placed on the opening of the insertion hole 02 formed in an object (e.g., cylinder) 05 so as to be in approximate alignment with the insertion hole 02. At this time, the axis of the inserting jig 01 and that of the insertion hole 02 are not in exact alignment with each other. In this state, an expander 03 having

plural fingers capable of expanding <sup>outwardly</sup> from the inside toward the outside is inserted into the insertion hole 02 and then the plural fingers are expanded outwards. As a result, the inserting jig 01 moves and the axis thereof comes into alignment with the axis of the insertion hole 02 (see Fig. 18) <sup>and is</sup> <sup>therein</sup> in this state the inserting jig 01 is fixed <sup>so as not to move</sup>.

Next, a work <sup>piece</sup> (e.g., piston) 04 is pushed in toward the insertion hole 02, while allowing to follow <sup>ing</sup> the tapered shape of the inserting jig 01, whereby the work 04 <sup>ing</sup> passes through the outlet of the inserting jig 01 and <sup>entering</sup> is inserted into the insertion hole 02 (see Fig. 19).

However, in such a conventional method which uses the inserting jig 01, it is necessary that the shape of the jig 01 be in conformity with the shape of the insertion hole; that is, it is necessary to provide inserting jigs <sup>a different</sup> 01 in a number corresponding to the number of <sup>for each</sup> types of insertion holes. Besides, <sup>03</sup> the expander 03 is also needed and an extra working time is required for the aligning work using the expander. Under these circumstances, in a multi-type mixed production line handling more than three types, the application of the method using the inserting jig 01 <sup>becomes</sup> is difficult. For example, in an engine assembling line <sup>an example of</sup> as a multi-type mixed production line, the process of inserting a piston into a cylinder bore is in many cases carried out by manual operation.

<sup>known</sup> [As another method using a jig <sup>disclosed in</sup> there] is known a method (Japanese Patent Laid Open No. 256526/92) <sup>In this later method</sup> wherein a position detecting jig is moved <sup>in</sup> and is allowed to follow an insertion hole while searching for the position of the insertion hole with use of a force control. In this method, however, a work chucking/inserting apparatus is required to shift the jig and a component from one to the other. This is time-consuming and a shift error occurs <sup>upon</sup> after repetition of <sup>each</sup> such jig shifting operation. [As] methods which

utilize similar tracing mechanisms <sup>disclosed in</sup> ~~there~~ are ~~known methods~~ <sup>Japanese Patent Laid Open Nos. 108108/93 and 168927/90</sup> <sup>in which methods</sup> wherein the position of an insertion hole is detected while allowing a work ~~itself~~ <sup>piece</sup> to contact and follow the insertion hole. But both methods involve problems such as the damage of components because the work itself is brought into contact with the insertion hole for detecting the position of the ~~same~~ <sup>same</sup> hole.

<sup>In</sup> Next, in case of using a Vision (a two-dimensional visual device), a positional deviation between a work <sup>piece</sup> and an insertion hole is detected by the Vision, position data <sup>for</sup> of a robot for chucking and conveying the work are corrected, and the work is inserted into the insertion hole at <sup>the</sup> an exact robot position. However, ~~since~~ the Vision is relatively expensive, <sup>an increase of</sup> ~~cost results.~~

<sup>No</sup> Moreover, the accuracy of the measurement made by the Vision <sup>can be no</sup> ~~does not become~~ higher than the resolution thereof, so for a highly accurate detection of the hole position it is necessary to take a close-up of the hole, requiring three or more cameras in the case of a large hole. <sup>Any</sup> ~~An attempt to~~ enhance the accuracy results in a further increase <sup>in</sup> of cost. <sup>Moreover</sup> ~~Besides,~~ <sup>a</sup> ~~correcting work~~ <sup>ion</sup> for matching both Vision and robot coordinate systems is troublesome and a complete matching is impossible, that is, the occurrence of ~~an~~ error is unavoidable. Mechanical changes <sup>e.g.,</sup> changes in weight and temperature, and shock, <sup>or</sup> a change in illumination, <sup>and</sup> a change in optical conditions of the hole also give rise to ~~an~~ error.

## SUMMARY OF THE INVENTION

It is an object of the present invention to provide a workpiece chucking/inserting apparatus capable of solving the above-mentioned problems <sup>as</sup> ~~involved in~~ the conventional means ~~which is~~ for inserting a workpiece.

into an insertion hole in alignment with the hole, also capable of handling various sizes of work<sup>pieces</sup> and capable of inserting a work<sup>piece</sup> into an insertion hole in an aligned state with the hole<sup>within</sup> a short time and<sup>with</sup> a high working efficiency, <sup>yet having</sup> with use of a simple structure.

For achieving the above-mentioned object, in<sup>a</sup> the first aspect of the present invention there is provided a work chucking/inserting apparatus to be used for chucking a work and inserting the work into an insertion hole in alignment with the hole, the work chucking/inserting apparatus including three or more chuck fingers, the chuck fingers being arranged in circumferentially spaced positions <sup>around a central axis</sup> and capable of advancing and retreating radially, inner surfaces of the chuck fingers serving as chuck surfaces for chucking the work, and outer surfaces of the chuck fingers being tapered at least at tip end portions, <sup>inward toward</sup> thereof so that the closer to the tips, the more inwards the taper, and capable of coming <sup>for</sup> into contact with an inlet of the insertion hole.

Since the work chucking/inserting apparatus in the first aspect of the invention is constructed as above, the outer surfaces of the three or more chuck fingers arranged in spaced circumferential positions assume a generally conical shape, which is suitable for searching for the position of a work insertion hole. When the outer surfaces of the plural chuck fingers having such a shape are brought into <sup>equal</sup> contact equally with the inlet of the insertion hole, it becomes possible to detect the position of the insertion hole accurately, and by a simple operation involving fixing the work chucking/inserting apparatus at to the detected position and pushing in the work as chucked by the inner surfaces of the chuck fingers toward the insertion hole, it is made possible to insert the work <sup>piece</sup> into the insertion hole in an aligned state with the hole. This can be done with an extremely

simple structure <sup>within</sup> and that <sup>with</sup> in a short time and a high working efficiency. In this case, the work chucking/inserting apparatus, after detecting the position of the insertion hole, memorizes the detected position and goes to a work feed <sup>location</sup> ~~place~~ <sup>retrieve a work</sup> to fetch the work.

<sup>Because</sup> Besides, the chuck fingers of the chucking/inserting apparatus can advance and retreat radially, so by adjusting the advance and retreat of the chuck fingers radially, in accordance with the size of the work, it is possible to chuck, or handle, various sizes of works. Thus, this work chucking/inserting apparatus is suitable for use in ~~an article~~ <sup>product</sup> assembling line as a multi-type mixed production line.

In the second aspect of the present invention there is provided a work chucking/inserting apparatus to be used for chucking a work and inserting the work into an insertion hole in alignment with the hole, the work chucking/inserting apparatus including three or more chuck fingers, the chuck fingers being arranged in circumferentially spaced positions and capable of advancing and retreating radially, inner surfaces of the chuck

<sup>Alternatively, the</sup> fingers serving as chuck surfaces for chucking the work, and <sup>have</sup> outer surfaces of the chuck fingers <sup>their</sup> having at least at tip end portions <sup>the central axis and to</sup> thereof surfaces parallel to an inner peripheral surface of the insertion hole, <sup>for</sup> and capable of being brought into contact with an inlet of the insertion hole.

<sup>Not</sup> Since the work chucking/inserting apparatus in the second aspect <sup>Thus, in this alternative</sup> of the invention is constructed as above, the outer surfaces of the three chuck fingers, arranged in spaced circumferential positions, assume a generally cylindrical shape, which is suitable for searching for the position of a work insertion hole. When the outer surfaces of the plural chuck fingers having such a shape are brought into <sup>equal</sup> contact Equally with the inlet of the insertion hole, it becomes possible to detect the position of the

insertion hole accurately, and by a simple operation involving fixing the work chucking/inserting apparatus <sup>91</sup> to the detected position and pushing in the work ~~as chucked by the inner surfaces of the chuck fingers toward the~~ insertion hole, it is made possible to insert the work into the insertion hole in an aligned state with the hole. This can be done with an extremely

simple structure and that in a short time and a high working efficiency. Also in this case, the work chucking/inserting apparatus, after detecting the position of the insertion hole, memorizes the detected position and goes to the work feed position to <sup>retrieve</sup> fetch the work.

Besides, the chuck fingers of this work chucking/inserting apparatus can advance and retreat radially, so by adjusting the advance and retreat of the chuck fingers radially in accordance with the work size it is possible to chuck, or handle, various sizes of works. Thus, this work chucking/inserting apparatus is suitable for use in an article assembling line as a multi-type mixed production line.

In <sup>another embodiment</sup> the third aspect of the present invention <sup>2</sup> there is provided a work chucking/inserting apparatus to be used for chucking a work and inserting the work into an insertion hole in alignment with the hole, the work chucking/inserting apparatus including three or more chuck fingers and three or more hole position detecting fingers, the chuck fingers being arranged in circumferentially spaced positions and capable of advancing and retreating radially, the hole position detecting fingers <sup>2/30</sup> being arranged in circumferentially spaced positions and pivotable inwards and outwards, <sup>about</sup> centered on base end portions thereof, <sup>as sulcrums</sup> ~~inner surfaces of the chuck fingers~~ <sup>As in the previously described embodiment,</sup> serving as chuck surfaces for chucking the work, and outer surfaces of the hole position detecting fingers <sup>are</sup> being tapered at least at tip end portions thereof, <sup>tapering inward toward</sup> so that the closer to the tips, the more inwards the taper, and <sup>for</sup>

[capable of coming into] contact with an inlet of the insertion hole.

No # → [Since the work chucking/inserting apparatus in the third aspect of the present invention is constructed as above, the outer surfaces of the three

~~or more~~ <sup>The</sup> hole position detecting fingers, which are arranged in circumferentially spaced positions, <sup>together define a</sup> so as to be pivotable inwards and

~~outwards with their base end portions as fulcrums, are~~ <sup>shape</sup> generally conical at

least at their tip end portions, which conical shape is suitable for searching

for the position of the work insertion hole. When the outer surfaces of the

plural hole position detecting fingers having such a shape are brought into

contact ~~equally~~ with the inlet of the insertion hole, it <sup>is</sup> becomes possible to

detect the position of the insertion hole accurately, <sup>As in the previously described embodiment</sup> and by a simple

operation <sup>fixes</sup> involving fixing a body portion of the work chucking/inserting

apparatus <sup>in</sup> to the detected position and <sup>allows</sup> pushing in the work ~~as chucked by~~

~~the inner surfaces of the chuck fingers toward the insertion hole, it is made~~

<sup>be pushed</sup> possible to ~~insert the work~~ into the insertion hole in an aligned state with

the hole. <sup>also</sup> Besides, in this case, the work chucking/inserting apparatus,

after detecting the position of the insertion hole, need not go to the work

feed <sup>location to retrieve</sup> place and fetch the work. Thus, with an extremely simple structure,

the work can be inserted into the insertion hole in an aligned state with the

hole in a short time and in a high working efficiency.

<sup>Because</sup> Besides, the chuck fingers <sup>of</sup> used in this work chucking/inserting

No # → apparatus <sup>also</sup> can advance and retreat radially, so by adjusting the advance

and retreat of the chuck fingers radially in accordance with the work size it

is possible to chuck, or handle, various sizes of works. Thus, this work

<sup>it also</sup> chucking/inserting apparatus is suitable for use in an article assembling

line as a multi-type mixed production line.

[In the fourth aspect of the present invention there is provided, in

~~3~~ ~~2~~ described second embodiment  
④ In combination with the above third aspect, a work chucking/inserting apparatus wherein the base end portions of the hole position detecting fingers <sup>may be</sup> [are] pivotally connected to tip end portions of the chuck fingers. According to this construction, when the work as chucked by the inner surfaces of the chuck fingers is inserted into the insertion hole, [it is] only [a] mechanical error between the hole position detecting fingers and the chuck fingers [that] comes into question. Since this error is very small and can be corrected relatively easily, the work can be inserted into the insertion hole accurately in alignment with the hole.

~~In the fifth aspect of the present invention there is provided, in~~  
④ ~~combination with the above third aspect, a work chucking/inserting~~  
<sup>Alternatively, in the second embodiment</sup>  
apparatus wherein the base end portions of the hole position detecting fingers <sup>may be</sup> [are] pivotally connected to a base portion <sup>on</sup> by which base end portions of the chuck fingers are <sup>slidably mounted</sup> [supported] for radial advance and retreat. According <sup>only</sup> to this construction, when the work as chucked by the inner surfaces of the chuck fingers is inserted into the insertion hole in alignment with the hole, [a] mechanical error between the hole position detecting fingers and the chuck fingers, through the base portion, comes into question. But since this error is relatively small and can be corrected, the work can be inserted into the insertion hole accurately in alignment with the insertion hole. <sup>Moreover</sup> [Besides], the hole position detecting fingers <sup>are</sup> [can be] pivotally supported in a more firm and stable manner.

~~In the sixth aspect of the present invention there is provided, in~~  
④ ~~combination with any of the above first to fifth aspects, a work~~  
<sup>may</sup>  
The chucking/inserting apparatus further including a tracer mechanism which, when the outer surfaces of the chuck fingers or of the hole position detecting fingers come into contact with the inlet of the insertion hole, causes the axis

of a conical surface defined by the outer surfaces of the three or more chuck fingers or of the three or more hole position detecting fingers to be aligned with the axis of the insertion hole. Thus, <sup>by advancing</sup> [by a mere operation of causing the outer surfaces of the chuck fingers or the hole position detecting fingers <sup>easily</sup> to advance] toward the insertion hole, it is possible to detect the position of the insertion hole, ~~that is, the position of the insertion hole can be detected~~ extremely easily.

~~In the seventh aspect of the present invention there is provided, in combination with any of the above first to sixth aspects, a work chucking/inserting apparatus further including a pushing mechanism for pushing the work toward the insertion hole. According to this construction,~~  
If the <sup>may</sup> chucking/inserting apparatus further including <sup>e</sup> a pushing mechanism for pushing the work toward the insertion hole. <sup>With pushing mechanism</sup> According to this construction, when the position of the insertion hole has been detected, the chuck fingers have chucked the work and the axis of a cylindrical surface formed by the inner surfaces of the chuck fingers has become aligned with the axis of the insertion hole, it immediately becomes possible to push the work into the insertion hole. Thus, <sup>within</sup> [in] a still shorter time and <sup>with</sup> [in] a still higher working efficiency, the work can be inserted into the insertion hole in alignment with the axis of the hole.

*insert from page 11/12*  
~~In the eighth aspect of the present invention there is provided, in combination with any of claims first to seventh, a work chucking/inserting apparatus wherein~~ the inlet of the insertion hole <sup>maybe</sup> [is] chamfered <sup>in which case the</sup> and tip end portions of the chuck fingers <sup>may have</sup> [are] respectively formed with projections <sup>for mating with</sup> [which] can fill up the chamfered portion when the work is inserted into the insertion hole. As a result, even if the inlet of the insertion hole is chamfered, an inner peripheral surface of the insertion hole and a cylindrical surface formed by the inner surfaces of the chuck fingers become contiguous to each other. Besides, the chuck fingers are received by the

chamfered portion and come to a standstill, so even if the work (e.g. piston) has a protuberance (e.g. piston ring) on its outer surface, the work can be inserted smoothly into the insertion hole (e.g., cylinder bore). Thus, such a protuberance is not an obstacle to an aligned insertion of the work into the insertion hole.

[In the ninth aspect of the present invention there is provided, in combination with any of the above first to eighth aspects, a work <sup>is suitable for use</sup> chucking/inserting apparatus wherein the work is a piston or an assembly of a piston and a connecting rod, and the insertion hole is a cylinder bore. According to this construction, the work for inserting the piston or the piston-connecting rod assembly into the insertion hole in alignment with the hole can be done with an extremely simple structure and that in a short time and in a high efficiency.]

No. 4 → [In the tenth aspect of the present invention there is provided, in combination with the above third aspect, a work chucking/inserting apparatus <sup>when</sup> wherein the work is an assembly of a piston and a connecting rod and the insertion hole is a cylinder bore, the chuck fingers chuck the piston, and the hole position detecting fingers also serve as means for chucking the connecting rod. According to this construction, the means for chucking the connecting rod can be constituted in an extremely simple manner without using any separate member.]

In the eleventh aspect of the present invention there is provided a work chucking/inserting apparatus to be used for chucking a work and inserting the work into an insertion hole in alignment with the hole, the work chucking/inserting apparatus including three or more chuck fingers, the chuck fingers being arranged in circumferentially spaced positions and capable of advancing and retreating radially, inner surfaces of the chuck

fingers serving as chuck surfaces for chucking the work and each having a portion tapered such that the closer to the tip thereof, the more inwards the taper, outer surfaces of the chuck fingers being tapered at least at tip end portions thereof so that the closer to the tips, the more inwards the taper, and capable of coming into contact with an inlet of the insertion hole, the

*insert to pg 9*  
The work chucking/inserting apparatus <sup>may</sup> ~~also~~ <sup>both</sup> including a tracer mechanism for causing the axis of a conical surface defined by the outer surfaces of the three or more chuck fingers to be aligned with the axis of the insertion hole when the said outer surfaces come into contact with the inlet of the insertion hole, and further including a pushing mechanism for pushing the work toward the insertion hole.

Since the work chucking/inserting apparatus in the eleventh aspect of the invention is constructed as above, not only it can exhibit the same effects as those mentioned in the above first, sixth and seventh aspects of the invention, but also it can attain the following effects.

The inner surfaces of the chuck fingers are formed as chuck surfaces for chucking the work, each having a portion tapered <sup>inward toward</sup> such that the closer to the tip thereof, the more inwards the taper, and the work chucking/inserting apparatus is further provided with a push mechanism for pushing the work toward the insertion hole. Therefore, even if the inner surfaces of the chuck fingers have already chucked the work when the work chucking/inserting apparatus ~~is detecting~~ the position of the insertion hole, the work chucking/inserting apparatus, after detection of the insertion hole position, stands still in the detected position and only the chuck fingers expand their tips radially outwards, permitting the work to pass therethrough. At this time, the pushing mechanism pushes <sup>to cause</sup> the work, allowing the work to slide on the tapered portions of the inner surfaces of

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danger of

the chuck fingers. As a result, without disengagement or drop of the work from the chuck fingers, the work can be inserted smoothly into the insertion hole while being guided by the tapered portions. Thus, after detection of the insertion hole position, the work chucking/inserting apparatus is not required to memorize the detected position and go to the work feed location to retrieve the work. In other words, it becomes possible to insert the work into

the insertion hole in alignment with the hole in a still shorter time and in a still higher working efficiency. Further, for eliminating the need of going to the work feed place and fetching the work it is no longer required to provide special hole position detecting fingers separately from the work chuck fingers, that is, the structure of the work chucking/inserting apparatus is not complicated.

In the twelfth aspect of the present invention there is provided, in combination with the above eleventh aspect, a work chucking/inserting apparatus wherein the inlet of the insertion hole is chamfered, and the tips of the outer surfaces of the chuck fingers are formed so that they can come into abutment against the chamfered portion when the work is inserted into the insertion hole. According to this construction there can be attained the same effect as in the above eighth aspect.

In the thirteenth aspect of the present invention there is provided a work chucking/inserting apparatus to be used for chucking a work and inserting the work into an insertion hole in alignment with the hole, the work chucking/inserting apparatus including three or more chuck fingers, the chuck fingers being arranged in circumferentially spaced positions and capable of advancing and retreating radially, inner surfaces of the chuck fingers serving as chuck surfaces for chucking the work and each having a portion tapered such that the closer to the tip thereof, the more inwards the

taper, end faces of the chuck fingers being flat at their portions except their portions close to their inner peripheral edges, and capable of coming into abutment against a wall surface which surrounds an inlet of the insertion hole, the said portions close to the inner peripheral edges being tapered such that the closer to the tips, the more inwards the taper, and capable of coming into contact with the inlet of the insertion hole, the inlet of the insertion hole being chamfered, the portions close to the inner peripheral edges of the end faces of the chuck fingers being capable of coming into abutment against the chamfered portion of the inlet of the insertion hole when the work is inserted into the insertion hole, the work chucking/inserting apparatus also including a tracer mechanism for causing the axis of a conical surface defined by the portions close to the inner peripheral edges of the end faces of the three or more chuck fingers to become aligned with the axis of the insertion hole when the portions close to the said inner peripheral edges come into contact with the inlet of the insertion hole, and the work chucking/inserting apparatus further including a pushing mechanism for pushing the work toward the insertion hole.

Since the work chucking/inserting apparatus in the thirteenth aspect of the invention is constructed as above, not only there can be attained the same effects as in the above eleventh and twelfth aspect but also the following effects can be obtained.

*In another embodiment*

~~Since~~ the end faces of the chuck fingers are flat <sup>for</sup> at their portions except <sup>for</sup> their portions close to their inner peripheral edges and can be brought into abutment against a wall surface which surrounds the inlet of the insertion hole, ~~and since the said~~ <sup>inwardly toward</sup> portions close to the inner peripheral edges are tapered <sup>for</sup> such that the closer to their tips, the more inwards the <sup>for</sup> taper, and can come into contact with the inlet of the insertion hole, the flat

portions of the end faces of the chuck fingers can be allowed to serve as positioning faces for positioning the work chucking/inserting apparatus ~~in~~ <sup>relative to</sup> axial ~~direction~~ of the insertion hole when the same apparatus detects the position of the insertion hole ~~by~~ utilizing the tapered portions close to the inner peripheral edges of the end faces of the chuck fingers. As a result, the work chucking/inserting apparatus can be <sup>fixed in position</sup> kept standstill in the axial ~~direction~~ of the insertion hole. <sup>In the foregoing manner</sup> besides, it is also possible to eliminate deflection of the axis and <sup>thereby</sup> hence possible to improve the accuracy in detecting the position of the insertion hole.

10 In the fourteenth aspect of the present invention there is provided, in combination with any of the above eleventh to thirteenth aspects, a work chucking/inserting apparatus wherein the work is a piston or an assembly of a piston and a connecting rod, and the insertion hole is a cylinder bore. According to this construction, there can be attained the same effect as in 15 the above ninth aspect.

In the fifteenth aspect of the present invention there is provided, in combination with any of the above eleventh to fourteenth aspects, a work ~~chucking/inserting apparatus wherein the~~ <sup>as mentioned</sup> pushing mechanism <sup>may have</sup> possesses a <sup>vacuum chucking</sup> work sucking function for <sup>holding</sup> sucking the work. <sup>With the vacuum chucking feature</sup> According to this construction,

20 even if the inner surfaces of the chuck fingers <sup>holding</sup> have already chucked the work before <sup>prior to</sup> the work chucking/inserting apparatus detects the position of the insertion hole, <sup>and</sup> when the tip ends of the outer surfaces of the chuck fingers are expanded radially outwards <sup>to allow</sup> due to passing of the work <sup>to pass</sup> therethrough or <sup>for</sup> detecting the position of the insertion hole, since the pushing mechanism <sup>holds by a vacuum</sup> sucks the work, there is no fear of disengagement <sup>or</sup> drop of the work from the work chucking/inserting apparatus, nor is there any fear of deflection of the apparatus <sup>axial orientation</sup> posture, thus permitting the work to

be inserted into the insertion hole positively and smoothly. <sup>Moreover,</sup> Besides, since the work is <sup>without sliding</sup> pushed by the pushing mechanism <sup>for slide</sup> on the tapered portions of the inner surfaces of the chuck fingers, there is no fear of damage to the work.

[In the sixteenth aspect of the present invention there is provided an assembling unit comprising] <sup>may be used to</sup> A robot [which] conveys the work chucking/inserting apparatus [described in any of the above first to fifteenth aspects up] <sup>to</sup> to the position of the insertion hole and [which] controls <sup>orientation</sup> the posture of the work chucking/inserting apparatus so that the work is inserted into the insertion hole in alignment with the hole.

No. 11  $\Rightarrow$  [According to the assembling unit in the above sixteenth aspect of the invention,] <sup>The</sup> a tracer control for [the work chucking/inserting apparatus] [which control is made to] <sup>ing</sup> detect the position of the insertion hole, the conveyance of the apparatus up to the position of the insertion hole, and [a] <sup>orientation of</sup> posture control for the apparatus with respect to the insertion hole, can be done automatically using the robot. <sup>all</sup>

#### BRIEF DESCRIPTION OF THE DRAWINGS

Fig. 1 is a perspective view showing the whole of an assembling unit equipped with an XYZ orthogonal coordinate robot on which is mounted a work chucking/inserting apparatus according to <sup>a</sup> [an embodiment] (the first embodiment) of the invention, ~~described in the above first, sixth, ninth and sixteenth aspects~~

Fig. 2 is a perspective view of the work chucking/inserting apparatus;

Fig. 3 is a perspective view of a posture control robot for controlling <sup>orientation</sup> the posture of the work chucking/inserting apparatus around  $\theta_x$ ,  $\theta_y$ ,  $\theta_z$ .

axes, which robot is interposed between the work chucking/inserting apparatus and the XYZ orthogonal coordinate robot;

Fig. 4 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of the work chucking/inserting apparatus; <sup>of the first embodiment</sup>

Fig. 5 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment <sup>the second embodiment</sup> of the invention, described in the above second aspect;

Fig. 6 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment <sup>the third embodiment</sup> of the invention, described in the above third and fourth aspects;

Fig. 7 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment <sup>the fourth embodiment</sup> of the invention, described in the above fifth aspect;

Fig. 8 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment <sup>the fifth embodiment</sup> of the invention, described in the above tenth aspect;

Fig. 9 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment <sup>the sixth embodiment</sup> of the invention, described in the above seventh aspect;

Fig. 10 is a diagram showing a modification of the sixth embodiment illustrated in Fig. 9;

Fig. 11 is an explanatory diagram showing, in a modeled form, the

structure of a principal portion of a work chucking/inserting apparatus according to an embodiment (the seventh embodiment) of the invention; described in the above eighth aspect;

Fig. 12 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment (the eighth embodiment) of the invention; described in the above eleventh, twelfth and fourteenth aspects;

Fig. 13 is a diagram showing a series of operations of the work chucking/inserting apparatus illustrated in Fig. 12 in a successive manner;

Fig. 14 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to an embodiment (the ninth embodiment) of the invention; described in the above thirteenth aspect;

Fig. 15 is a diagram showing a series of operations of the work chucking/inserting apparatus illustrated in Fig. 14 in a successive manner;

Fig. 16 is a diagram showing, in a successive manner, a series of operations of a work chucking/inserting apparatus according to an embodiment (the tenth embodiment) of the invention; described in the above fifteenth aspect;

Fig. 17 is a diagram showing an operational step of inserting <sup>of</sup> a work into an insertion hole with use of a conventional inserting jig;

Fig. 18 is a diagram showing another step using the conventional inserting jig; and

Fig. 19 is a diagram showing a further step using the conventional inserting jig.

## DETAILED DESCRIPTION OF PREFERRED EMBODIMENTS

~~The following description is now provided about an embodiment~~  
~~(the first embodiment) of the invention described in the above first, sixth,~~  
~~ninth and sixteenth aspects, which is illustrated in Figs. 1 to 4.~~  
*will now be with reference to*

Fig. 1 is a perspective view showing the whole of an assembling unit equipped with an XYZ orthogonal coordinate robot on which is mounted a work chucking/inserting apparatus according to this first embodiment, Fig. 2 is a perspective view of the work chucking/inserting apparatus, Fig. 3 is a perspective view of a posture control robot for controlling the posture of the work chucking/inserting apparatus around  $\theta_x$   $\theta_y$   $\theta_z$  axes which robot is interposed between the work chucking/inserting apparatus and the XYZ orthogonal coordinate robot, and Fig. 4 is an explanatory diagram showing the structure of a principal portion of the work chucking/inserting apparatus in a modeled form.

The work chucking/inserting apparatus of this first embodiment is used for inserting <sup>a</sup>piston into a cylinder bore in alignment with the bore in an internal combustion engine assembling process. As shown in Fig. 1, in an assembling unit 1 for inserting a piston into a cylinder bore, a work support base 10 is installed centrally of a <sup>platform</sup> floor 2, a first XYZ orthogonal coordinate robot (hereinafter referred to as "the first robot") is installed on the right-hand side in Fig. 1 of the <sup>platform</sup> floor 2, and a second XYZ orthogonal coordinate robot ("the second robot" hereinafter) 30 is installed on the left-hand side in Fig. 1 of the <sup>platform</sup> floor 2. Between the work support base 10 and the first robot 20 is provided a temporary work rest 40.

The work support base 10 is provided on top thereof with a turntable 12 on which is placed a cylinder block 11 as one <sup>workpiece</sup> work. For inserting an assembly (see Fig. 2, hereinafter referred to simply as

"assembly") 61 of a piston 62 and a connecting rod 63 into a cylinder bore 13 of the cylinder block 11, the first robot 20 carries the assembly 61 up <sup>to the</sup> ~~position~~ <sup>adjacent</sup> of the cylinder bore 13. The second robot 30 <sup>inserts</sup> carries a pair of chuck arms 31 through an opposite-side opening of the cylinder bore 13 <sup>into</sup> up to the interior of the bore, the chuck arms 31 functioning to chuck and guide a tip end portion of the connecting rod 63 to be inserted into the cylinder bore 13. On the temporary work rest 40 are rested a plurality of assemblies 61, <sup>pieces</sup> [as the] other work, standing by for <sup>insertion</sup> [the work inserting operation] into <sup>the</sup> cylinder bore <sup>s</sup> 13. The cylinder block 11 <sup>has</sup> is for four cylinders; <sup>and</sup> that is, there are provided four cylinder bores 13 and four assemblies 61.

As shown in Fig. 2, each assembly 61 is chucked by the work chucking/inserting apparatus of this embodiment, indicated at 60. As shown in Fig. 3, the work chucking/inserting apparatus 60 is supported by a posture control robot 50. The posture control robot 50 is equipped with motors 51, 52 and 53 around three shafts  $\theta_x$ ,  $\theta_y$ ,  $\theta_z$  for correcting <sup>orientation</sup> [an] axial [deflection] and <sup>orientation</sup> [a] rotational [deflection] of the assembly 61. As shown in Fig. 1, the posture control robot 50 is fixedly secured to a Y shaft of the first robot 20 and is thereby supported by the first robot 20.

Next, reference will be made below to the structure of the work chucking/inserting apparatus 60.

As shown in Fig. 2, the work chucking/inserting apparatus 60 has six piston chuck fingers 65 projecting in a leftward and downward direction in Fig. 2 from a base portion 64 of the apparatus. The six piston chuck fingers 65 are arranged circumferentially at equal intervals <sup>around a central axis</sup> and can advance and retreat radially. Inner surfaces of the chuck fingers 65 serve as chuck surfaces for chucking the piston 62, while outer surfaces thereof are tapered at least at their tip end portions so that the closer to their tips,

the more inwards the taper. The shape formed by combination of all the six piston chuck fingers 65 is a tapered shape which is narrower at their tips, and the outer surfaces thus tapered of the piston chuck fingers can contact <sup>the</sup> an inlet of the cylinder bore 13 being opened toward the first robot 20 side. In the illustrated embodiment, chuck fingers 65 are tapered over the greater part <sup>of their length</sup> in the longitudinal direction thereof in such a manner that the closer to their tips, the more inwards the taper. The tapers <sup>of portions</sup> of the outer surfaces of the piston chuck fingers 65 are arranged on a single (virtual) conical surface. The number of the piston chuck fingers 65 is three or more.

10 [If] the piston chuck fingers 65 are arranged in circumferentially spaced <sup>and</sup> positions, [it will do. But] preferably [they are arranged] at equal intervals <sup>circumferential</sup> [in] the circumferential direction.]

15 The mechanism for causing the piston chuck finger 65 to advance and retreat radially on the base portion 64 is a known mechanism. Though not shown, a pin <sup>is</sup> projected <sup>from</sup> on the back of a leg portion of each piston chuck finger 65, and a cam plate formed with a cam groove, which the pin follows, <sup>provided</sup> is accommodated in the interior of the base portion 64. As the cam plate rotates forward and reverse, the pin reciprocates in the cam groove in a relative manner and the piston chuck finger 65 integral with the pin  
20 advances and retreats radially. The rotation of the cam plate is performed by a motor 66.

An air chuck 67 is attached integrally to the base portion 64 and a pair of connecting rod chucking arms 68 extend from the air chuck 67 in the same direction as the piston chuck fingers 65. The connecting rod chucking arms 68 are L-shaped and the tips of their L shapes chuck <sup>the wider</sup> a large <sup>end</sup> [diameter side] of the connecting rod 63 in alignment with the piston 62, the connecting rod 63 being <sup>attached</sup> mounted to the piston 62. By <sup>supplying</sup> permitting or cutting

off the supply of air pressure to the air chuck 67, the paired connecting rod chucking arms 68 <sup>are swung</sup> ~~swing~~ toward or away from each other. When the arms 68 swing toward each other, they chuck the <sup>wider end</sup> ~~large-diameter side~~ of the connecting rod 63.

A force sensor 69 is integral with the back (in Fig. 2) of the base portion 64. When the outer surfaces of the six piston chuck fingers 65 are brought into pressure contact with the inlet of the cylinder bore 13 (see Fig. 4) for detecting the position of the cylinder bore, the force sensor 69 detects the magnitude and direction of a resultant force  $F$  of reaction forces which the piston chuck fingers 65 receive from the <sup>wall of the</sup> ~~cylinder~~ bore 13. The resultant force  $F$  of the reaction forces comprises force components  $F_x$ ,  $F_y$ ,  $F_z$  and rotational force components  $F_{\theta x}$ ,  $F_{\theta y}$ ,  $F_{\theta z}$  acting around the axis  $\theta_x$ ,  $\theta_y$  and  $\theta_z$  <sup>respectively</sup>. Therefore, the resultant force  $F$  of <sup>the</sup> ~~reaction~~ forces which the piston chuck fingers 65 receive from the <sup>wall of the</sup> ~~cylinder~~ bore 13 can be expressed as follows:

$$F = F(F_x, F_y, F_z, F_{\theta x}, F_{\theta y}, F_{\theta z})$$

<sup>The</sup> ~~That~~ the force components  $F_x$ ,  $F_z$ ,  $F_{\theta x}$ ,  $F_{\theta y}$  and  $F_{\theta z}$  ~~are present~~ indicates ~~that~~ <sup>the</sup> ~~there occurs~~ a relative positional deviation between the cylinder bore 13 and <sup>the</sup> ~~a~~ virtual conical surface defined by the outer surfaces of the six piston chuck fingers 65 or <sup>the</sup> ~~a~~ virtual cylindrical surface (chuck surface) defined by the inner surfaces of the six piston chuck fingers. In this connection, if ~~the~~ <sup>the</sup> presence of the force components  $F_x$ ,  $F_z$ ,  $F_{\theta x}$ ,  $F_{\theta y}$  and  $F_{\theta z}$  <sup>are</sup> ~~is~~ detected, the position of the work chucking/inserting apparatus having the six piston chuck fingers 65 is corrected repeatedly by ~~a~~ <sup>by</sup> movement ~~quantity control~~ in XZ directions ~~with~~ use of the first robot 20 and also by ~~a~~ <sup>by</sup> rotational ~~quantity control~~ around the  $\theta_x$ ,  $\theta_y$  and  $\theta_z$  axes ~~with~~ use of the posture control robot 50, ~~which controls are made~~ so that

those force components are eliminated, that is, <sup>the</sup> ~~there remains~~ only the force component  $F_y$  in Y direction.

In this way the position of the work chucking/inserting apparatus 60 is corrected repeatedly following the position of the cylinder bore 13. When the aforesaid force components have been eliminated or almost eliminated, the position of the work chucking/inserting apparatus 60 can be regarded as corresponding to <sup>the</sup> ~~an~~ exact position of the cylinder bore 13. At this time, the axis of a single conical surface defined by the outer surfaces of the six piston chuck fingers 65 and the axis of a single cylindrical surface defined by the inner surfaces of the six piston chuck fingers are aligned with the axis of the cylinder bore 13, and the position of the work chucking/inserting apparatus 60 is memorized.

Since the six piston chuck fingers 65 of the work chucking/inserting apparatus 60, the first robot 20 and the posture control robot 50 function as above, it can be said that they combine together to constitute a tracer mechanism for detecting the position of the cylinder bore 13.

<sup>In</sup> ~~According to~~ such a method for detecting the position of the cylinder bore 13, <sup>the extent of</sup> ~~relative~~ positional deviation <sup>that of</sup> ~~quantity~~ and rotational deviation ~~quantity~~ of the cylinder bore 13 with respect to the work chucking/inserting apparatus 60, are detected as electrical values and instructions are given to controllers of the first robot 20 and the posture control robot 50, causing the work chucking/inserting apparatus 60 to move <sup>the</sup> ~~in~~ XZ plane or <sup>to</sup> ~~rotate~~ around the XYZ ~~rotary~~ shafts so as to eliminate those deviations. Instead of such an electrical method there may be adopted a mechanical method.

~~As~~ <sup>An</sup> example of a mechanical method ~~there~~ <sup>is</sup> ~~known~~ <sup>a</sup> method using a floating mechanism. According to this method, a floating

mechanism is used as a substitute for the force sensor 69 used in the above electrical method. In this case, the tip end portion of the work chucking/inserting apparatus 60, i.e., the tips of the six piston chuck fingers 65 of the work chucking/inserting apparatus 60, are brought into pressure contact with the inlet of the cylinder bore 13 and are then inched longitudinally (in <sup>the</sup> Y direction). As a result, the floating mechanism <sup>allows</sup> [operates and] the work chucking/inserting apparatus 60 <sup>to</sup> slides <sup>the</sup> in XZ plane, permitting an automatic alignment.

As shown in Figs. 2 and 3, a mounting arm 70 projects from the back of the force sensor 69 attached to the work chucking/inserting apparatus 60 and is secured rotatably to a third frame 54 of the posture control robot 50, whereby the work chucking/inserting apparatus 60 is suspended from the posture control robot 50. A motor 51 is fixed to the third frame 54 and a rotary shaft thereof is connected to the mounting arm 70 so as <sup>prevent</sup> [not] to [permit] a relative rotation thereof. Thus, with the motor 51, the work chucking/inserting apparatus 60 <sup>be</sup> can rotate around the  $\theta_x$  axis. The third frame 54 is suspended from a second frame 55 so that it can be rotated around the  $\theta_y$  axis by means of a motor 52.

The second frame 55 is suspended from a first frame 56 so that it can be rotated around the  $\theta_z$  axis by means of a motor 53. The first frame 56 is fixed to the Y shaft of the first robot 20. In this way the posture control robot 50 is supported by the first robot 20.

Since the work chucking/inserting apparatus 60 is thus suspended <sup>from</sup> [by] the posture control robot 50 and the posture control robot 50 is thus supported by the first robot 20, it becomes possible to <sup>detect</sup> [effect] the position <sup>of</sup> [detection for] the cylinder bore 13, <sup>ing</sup> [which] utilizes the tracer mechanism and an aligned insertion of an assembly 61 ~~[which will be described later]~~ into the

cylinder bore 13.

A more detailed description will be given below <sup>of</sup> about the operations of the work chucking/inserting apparatus 60, the posture control robot 50 and the first and second robots 20, 30.

When the position of the cylinder bore 13 is detected in the manner described above, the axis of the cylinder bore 13 and that of a single conical surface defined by the arrangement of the outer surfaces of the six piston chuck fingers 65 or of a single cylindrical surface defined by the arrangement of the inner surfaces of the six piston chuck fingers are aligned with each other and the position of the work chucking/inserting apparatus 60 (the position <sup>s</sup> on the XYZ shafts and a rotational position <sup>s</sup> around the  $\theta_x$   $\theta_y$   $\theta_z$  axes) in this instant <sup>are</sup> is memorized. Therefore, the first robot 20 then leaves the detected position of the cylinder bore 13 and conveys the work chucking/inserting apparatus 60 up to the position of the temporary work (piston) rest 40.

At this time, the axis of a single conical surface defined by the arrangement of the outer surfaces of the six piston chuck fingers 65 is oriented rendered vertical and the six piston chuck fingers 65 are moved so as to become positioned just above a specific piston 62 placed on the temporary work rest 40. The six piston chuck fingers 65 are then moved further downward by the first robot 20 and the motor 66 is turned ON to let the piston chuck fingers 65 advance and retreat radially, whereby the piston chuck fingers 65 can chuck the piston 62. The connecting rod 63 is integral with the piston 62 and is chucked by the paired connecting rod chucking arms 68 in alignment with the piston 62 when the piston chuck fingers 65 ~~chucks~~ the piston 62.

When the six piston chuck fingers 65 have thus chucked the piston

62, the first robot 20 conveys the work chucking/inserting apparatus <sup>[up]</sup> to the pre-memorized position on the XZ shafts, and the posture control robot 50 causes the work chucking/inserting apparatus 60 to rotate <sup>[up]</sup> to the pre-memorized rotational position<sup>s</sup> around the  $\theta_x$ ,  $\theta_y$ ,  $\theta_z$  axes, now ready for the start of <sup>the</sup> operation for inserting the assembly 61 into the cylinder bore 13.

Then, the first robot 20 conveys the work chucking/inserting apparatus 60 along the Y shaft until the six piston chuck fingers 65 come into abutment against an end face of the inlet of the cylinder bore 13 and inserts the assembly 61 into the cylinder bore 13 from the tip end side of the connecting rod 63. Upon this insertion of the assembly 61 into the cylinder bore 13 the paired chuck arms 31 which have been moved into the cylinder bore 13 from the opposite-side opening of the bore, and which are now in a stand-by state, chuck the tip end portion of the connecting rod 63, then the paired connecting rod chucking arms 68 release the connecting rod 63 and retreat. At the same time, the paired chuck arms 31 also retreat. As a result, the piston 62 is <sup>inserted</sup> ~~drawn~~ into the cylinder bore 13. ✓

When the six piston chuck fingers 65 have come into abutment against the end face of the inlet of the cylinder bore 13, their <sup>outer</sup> ~~inner~~ surfaces are flush with the inner peripheral surface of the cylinder bore 13, and the axis of the cylindrical surface defined by the inner surfaces of the piston chuck fingers 65 is aligned with the axis of the cylinder bore 13, so that the piston 62 is inserted smoothly into the cylinder bore 13.

~~The above operations are repeated for each of plural cylinder bores 13.~~

~~Since this first embodiment is constructed as above, it is possible to obtain the following effects~~

~~The work chucking/inserting apparatus 60 used for inserting the~~

piston 62 into the cylinder bore 13 in alignment with the bore has six piston chuck fingers 65, the piston chuck fingers 65 being arranged circumferentially at equal intervals and capable of advancing and retreating radially, the inner surfaces of the piston chuck fingers 65 serving as chuck surfaces for chucking the piston 62, the outer surfaces of the piston chuck fingers 65 being tapered at least at their tip end portions so that the closer to their tips, the more inwards the taper, and capable of coming into contact with the inlet of the cylinder bore 13.

*noted above*  
As ~~a~~ result, the outer surfaces of the six piston chuck fingers 65 arranged circumferentially at equal intervals define a generally conical shape, which shape is suitable for searching for the position of the insertion hole (cylinder bore 13) for the piston 62. When the outer surfaces of the six piston chuck fingers 65 having such a shape are brought into contact equally with the inlet of the cylinder bore 13, it becomes possible to detect the position of the cylinder bore 13 accurately, and by merely fixing the work chucking/inserting apparatus 60 <sup>in</sup> ~~to~~ the detected position and pushing (drawing) the piston 62, chucked by the inner surfaces of the six piston chuck fingers 65, toward the cylinder bore 13, it <sup>becomes</sup> ~~is made~~ possible to insert the piston 62 into the cylinder bore 13 in alignment with the bore. Thus, with an extremely simple structure, the piston 62 can be inserted into ~~and~~ <sup>and</sup> aligned with the cylinder bore 13 in a short time and <sup>with</sup> ~~in a~~ high working efficiency.

*Because*  
[Besides,] the six piston chuck fingers 65 of the work chucking/inserting apparatus 60 can be advanced and retreated radially, <sup>so</sup> ~~so~~ by adjusting the radial advance and retreat of the chuck fingers 65 in accordance with the size of the piston 62, it is possible to chuck, or handle, various sizes of pistons 62 and thus the work chucking/inserting apparatus

60 is suitable for an engine assembling line <sup>which is</sup> [as] a multi-type mixed production line.

Moreover, in the case where the work chucking/inserting apparatus 60 is provided with a tracer mechanism so that the axis of a conical surface defined by the outer surfaces of the six piston chuck fingers 65 is aligned with the axis of the cylinder bore 13 when the ~~said~~ outer surfaces contact the inlet of the cylinder bore 13, [a] mere operation of advancing the outer surfaces of the piston chuck fingers 65 toward the cylinder bore 13 permits detection of the cylinder bore 13 position, and thus the position of the cylinder bore 13 can be detected extremely easily.

Further, since the assembling unit 1 is equipped with a robot for conveying the work chucking/inserting apparatus 60 [up] to the position of the cylinder bore 13 and for controlling the <sup>orientation</sup> [posture] of the work chucking/inserting apparatus 60 so that the piston 62 is inserted into the cylinder bore 13 in alignment with the bore, [a] tracer control [for the work] ~~chucking/inserting apparatus 60 which is made~~ for detecting the position of the cylinder bore 13, conveyance of the work chucking/inserting apparatus 60 [up] to the position of the cylinder bore 13 and <sup>orientation of</sup> [a posture] control [for] the work chucking/inserting apparatus 60 with respect to the cylinder bore 13 can all be done automatically by utilizing the robot.

<sup>A</sup> ~~Description will be directed below to an embodiment (the) second embodiment~~ of the invention <sup>will now be</sup> described <sup>with reference to</sup> [in] the foregoing second aspect,

[which is illustrated in] Fig. 5.

Fig. 5 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the second embodiment.

In the work chucking/inserting apparatus of the second

embodiment, indicated at 60, outer surfaces of six piston chuck fingers 65 are not tapered at their tip end portions 65a, but are arranged on a single (virtual) cylindrical surface, which is formed so as to become parallel to the inner peripheral surface of the cylinder bore 13 when the axis of the cylindrical surface and that of the cylinder bore 13 are aligned with each other. Therefore, when the six piston chuck fingers 65 are <sup>retracted</sup> ~~retreated~~ radially, the tip end portions 65a of the outer surfaces of the six piston chuck fingers 65 can contact the inner peripheral surface of the inlet portion of the cylinder bore 13. *Otherwise,*

*No* ~~In the point just described above the second embodiment is different from the previous first embodiment, but~~ there is nothing else <sup>of the other features of the second embodiment</sup> different from the first embodiment, so a detailed description thereof will be omitted.

*With* ~~Since~~ the second embodiment <sup>is</sup> constructed as above, if ~~how the~~ <sup>actions</sup> contact pressure varies among the six piston chuck fingers 65, upon contact of the tip end portions 65a of their outer surfaces with the inner peripheral surface of the inlet portion of the cylinder bore 13, <sup>are</sup> is detected with use of <sup>such</sup> ~~the~~ force sensor as the force sensor 69 used in the first embodiment, it is possible to detect the position of the cylinder bore 13. In addition, there can be attained the same effects as in the first embodiment. In this second embodiment, the mechanical method using a floating mechanism is most suitable for detecting the position of the cylinder bore 13.

*CH* ~~Next, a description will be given below about an embodiment (the~~ <sup>will now be</sup> ~~third embodiment)~~ of the invention described <sup>with reference to</sup> in the foregoing third and fourth aspects, which is illustrated in Fig. 6.

~~Fig. 6 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus~~

according to the third embodiment.

In the work chucking/inserting apparatus of this third embodiment, indicated at 60, <sup>the</sup> a position detecting function <sup>as detecting the</sup> for the insertion hole <sup>the function of</sup> cylinder bore 13) and a work (piston 62) chucking and inserting function are imparted to two separate members <sup>respectively</sup>. In this <sup>respective</sup> point the third embodiment is different from the <sup>previous</sup> first embodiment. More specifically, inner surfaces of piston chuck fingers 65 serve as chuck surfaces for chucking the piston 62, but outer surfaces thereof are not <sup>involved</sup> concerned in detecting the position of the cylinder bore 13. It is <sup>the</sup> hole position detecting fingers 71, separate from the piston chuck fingers 65 that <sup>serve to</sup> are concerned in detecting the position of the cylinder bore 13.

The hole position detecting fingers 71 are provided in the same number, i.e., six, as the piston chuck fingers 65 and are arranged circumferentially at equal intervals. Base end portions of the hole position detecting fingers 71 are pivotally connected to tip end portions of the piston chuck fingers 65 so as to be pivotable inwards and outwards with their pivoted base ends as fulcrums. Like the outer surfaces of the piston chuck fingers 65 in the first embodiment, at least tip end portions 71a of the outer surfaces of the hole position detecting fingers 71 are tapered <sup>inward</sup> such that the <sup>toward</sup> closer to their tips, the more inwards the taper, and can <sup>with</sup> contact the inner peripheral surface of the inlet portion of the cylinder bore 13.

The piston chuck fingers 65 and the hole position detecting fingers 71 <sup>as</sup> both used in this third embodiment combine together to <sup>provide</sup> exhibit the same function <sup>as those</sup> as that of the piston chuck fingers 65 used in the first embodiment.

The piston chuck fingers 65 used in the first embodiment correspond to <sup>the</sup> a <sup>combined</sup> united one of both piston chuck fingers 65 and hole position detecting fingers 71 used in the third embodiment. After the hole position detecting

detected  
fingers 71 have played the role of detecting the position of the cylinder bore 13, they are pivotally moved outwards and are therefore not an obstacle to the insertion of the piston 62 into the cylinder bore 13. Otherwise, this

No 11 This third embodiment is different in the above point from the first embodiment, but there is nothing else different from the first embodiment, so a further detailed explanation thereof will be omitted.

In Since the work chucking/inserting apparatus 60 of the third embodiment is constructed as above, the hole position detecting fingers 71 can fulfill the role of detecting the position of the cylinder bore 13 while the piston chuck fingers 65 continue to chuck the piston 62. Thus, it is not necessary for the work chucking/inserting apparatus to go to the temporary rest of the piston 62 and fetch the piston 62. Consequently, the piston 62 can be inserted into and aligned with the cylinder bore 13 in a still shorter time and with a still higher working efficiency than in the first embodiment.

Moreover, Besides, since the base end portions of the hole position detecting fingers 71 are pivotally connected to the tip end portions of the piston chuck fingers 65, it is only a mechanical error between the hole position detecting fingers 71 and the piston chuck fingers 65 that comes into question at the time of inserting the piston 62 into the cylinder bore 13 in alignment with the bore which piston is chucked by the inner surfaces of the piston chuck fingers 65. Since this error is very small and can be corrected easily, the piston 62 can be inserted into and aligned with the cylinder bore 13 more accurately. In addition, there can be attained the same effects as in the first embodiment.

The following description is now provided about an embodiment (the fourth embodiment) of the invention will now be described in the foregoing fifth aspect, which is illustrated in Fig. 7.

Fig. 7 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the fourth embodiment.

In the work chucking/inserting apparatus <sup>60</sup> of the fourth embodiment, [indicated at 60] base end portions of six hole position detecting fingers 71 are pivotally connected to an outer periphery of a base portion 64.

~~Other~~<sup>54</sup> ~~in the above point~~ this fourth embodiment is ~~different from~~ <sup>the same as</sup> the [previous] third embodiment, ~~but there is nothing else different from the~~ <sup>synthetic</sup> third embodiment, so a detailed description thereof will be omitted.

<sup>In</sup> [Since] the fourth embodiment [is] constructed as above, the hole position detecting fingers 71 <sup>are</sup> [can be] pivotally supported more firmly and stably than in the third embodiment. <sup>Otherwise, the effects are</sup> [In addition, there can be attained] substantially the same [effects] as in the third embodiment.

A ~~description will be given below about an embodiment (the~~ fifth embodiment) <sup>will now be</sup> of the invention described <sup>with reference to</sup> in the foregoing tenth aspect, which is illustrated in Fig. 8.

Fig. 8 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the fifth embodiment.

In the work chucking/inserting apparatus <sup>60</sup> of this fifth embodiment, [indicated at 60] two of the six hole position detecting fingers 71 used in the fourth embodiment serve also as a pair of connecting rod chucking arms 68 (see Fig. 2) [which are means] for chucking the connecting rod 63.

→ To this end, the two hole position detecting fingers 71 are respectively formed with extending portions 71b which reach the connecting rod 63 at more inward positions than the tip end portions 71a of the outer surfaces which are tapered for detecting the position of the cylinder bore 13.

The remaining four hole position detecting fingers 71 do not have such extending portions 71b, but are of the same shape, <sup>excluding</sup> as the extending portions 71b <sup>as the</sup> excluded shape of the above two hole position detecting fingers 71.

*no #* <sup>Otherwise,</sup> [In the above point] this fifth embodiment is <sup>the same as</sup> [different from] the [previous] fourth embodiment, [but there is nothing else different from the] fourth embodiment, <sup>further</sup> so a detailed explanation thereof will be omitted. <sup>provides a more simplified structure in that</sup> [Since] the fifth embodiment [is constructed as above,] the paired connecting rod chucking arms 68 <sup>are not</sup> [can be constituted in an extremely simple] manner without using any separate member <sup>3</sup> different from the hole position detecting fingers 71. <sup>Otherwise, this third embodiment provides</sup> [In addition, there can be obtained] the same effects as in the fourth embodiment.

[In] the fifth embodiment it is not limited to the two hole position detecting fingers 71 that are <sup>used</sup> also as the paired connecting rod chucking arms 68. Four hole position detecting fingers, [may be divided into] two on the right-hand side and two on the left-hand side, [and the resulting] [two pairs] may be used for the same purpose. There also may be adopted a modification wherein one or two hole position detecting fingers 71 are attached to each of the paired connecting rod chucking arms 68.

~~[Reference will now be made to an embodiment (the) sixth embodiment] of the invention <sup>will now be</sup> described [in the foregoing seventh aspect,] <sup>with reference to</sup> which is illustrated in Fig. 9.~~

~~Fig. 9 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the sixth embodiment.~~

<sup>60</sup>  
In the work chucking/inserting apparatus of this sixth embodiment, [indicated at 60] there is provided a pushing mechanism 72 for pushing the piston 62 <sup>piece</sup> ~~as the~~ toward the cylinder bore 13 ~~as the~~ (insertion hole).

The pushing mechanism 72 is fixed to a base portion 64 on the side where piston chuck fingers 65 are provided, and <sup>includes</sup> it is provided with a cylinder 73 and a plunger 74 projecting from the cylinder 73. The plunger 74 is <sup>extended</sup> pushed with a pneumatic pressure or a hydraulic pressure and is thereby projected from the cylinder 73, whereby the piston 62 is pushed toward the cylinder bore 13 and is inserted into the cylinder bore 13. <sup>Alternately,</sup> The pushing mechanism 72 may be constituted electrically.

The pushing mechanism 72 used in this sixth embodiment is applicable to any of the previous first to fifth embodiments. <sup>Otherwise,</sup> In this sixth embodiment, <sup>is not</sup> except the above point there is nothing else particularly different from <sup>the</sup> those previous <sup>is described</sup> embodiments, so a detailed description thereof will be omitted.

<sup>With</sup> Since the sixth embodiment is constituted as above, when the position of the cylinder bore 13 is detected and the ~~sixth~~ piston chuck fingers 65 chuck the piston 62, and upon alignment of the axis of a (virtual) cylindrical surface defined by the inner surfaces of the piston chuck fingers 65 with the axis of the cylinder bore 13, it becomes possible to push the piston 62 into the cylinder bore 13. Thus, the piston 62 <sup>aligned with and</sup> can be inserted into and aligned with the cylinder bore 13 in a shorter time and <sup>with</sup> in a higher working efficiency. <sup>Moreover</sup> Besides, since the Y shaft of the first robot 20 is not used for pushing the piston 62 into the cylinder bore 13, the piston 62 can be inserted into the cylinder bore 13 with a high accuracy while allowing the piston chuck fingers 65 to substantially stand still.

When the piston 62 is to be pushed into the cylinder bore 13, the piston chuck fingers 65 are slightly <sup>retracted</sup> retreated radially, so that the chucking force of the ~~sixth~~ piston chuck fingers 65 for the piston 62 is <sup>reduced</sup> weakened slightly, whereby the piston 62 is allowed to move toward the cylinder bore

13 while sliding on a cylindrical surface defined by the inner surfaces of the six piston chuck fingers 65. Thus, the piston 62 can be inserted into the cylinder bore 13 smoothly while <sup>maintaining orientation</sup> preserving its posture without any damage thereto. <sup>while providing</sup> In addition, there can be attained the same effects as in the previous first to fifth embodiments.

Fig. 10 illustrates a modification of the above sixth embodiment. In this modification, the piston 62 is provided with a piston ring 75 on its outer peripheral surface. The piston ring 75 is fitted in an annular groove formed in the outer peripheral surface of the piston 62 and <sup>is</sup> possesses resilience. Therefore, a contact force most suitable for the piston ring 75 to slide on the inner chuck surfaces of the piston chuck fingers 65 can be obtained easily by adjusting the <sup>extent of retraction</sup> return quantity (retreat quantity) of the piston chuck fingers 65.

<sup>A</sup> Description will now be directed to an embodiment (the seventh embodiment) <sup>will now be described with reference to</sup> of the foregoing eighth aspect, which is illustrated in Fig. 11.

Fig. 11 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the seventh embodiment of the present invention.

In the work chucking/inserting apparatus <sup>60</sup> of this seventh embodiment, indicated at 60, the inlet of the cylinder bore 13 is chamfered at 76, while tip end portions of six piston chuck fingers 65 are respectively formed with projections 77 which <sup>mate with</sup> can fill up the chamfered portion 76. Therefore, when the tips of the six piston chuck fingers 65 are <sup>put in</sup> abutment <sup>ted</sup> against the inlet end faces of the cylinder bore 13, upon insertion of the piston 62 chucked by the six piston chuck fingers 65 into the cylinder bore 13, the projections 77 <sup>mate with</sup> can fill up the chamfered portion 76. <sup>in that</sup> abutted position.

The chamfered structure of the inlet of the cylinder bore 13 and the projection structure of the tip end portions of the piston chuck fingers 65 <sup>which mate with</sup> capable of filling up the chamfered portion both adopted in this seventh embodiment, are applicable to all of the first to sixth embodiments. Particularly, in the case where the tip end portions of the outer surfaces of the piston chuck fingers 65 are tapered as in the first embodiment, this taper structure can be utilized in <sup>accordance with this seventh embodiment</sup> the above projection structure (see chain lines in Fig. 11). <sup>Otherwise,</sup> In this seventh embodiment there is <sup>the same as</sup> nothing else <sup>the</sup> different from those previous <sup>described</sup> embodiments, so a <sup>further</sup> detailed explanation thereof will be omitted.

<sup>With</sup> Since the seventh embodiment is constructed <sup>described</sup> as above, a continuous annular recess (groove) of a wedge-like section is not formed in the chamfered portion 76 when the piston 62 is inserted into the cylinder bore 13. Consequently, there is no fear of the front edge of the piston 62 being caught in <sup>such an</sup> the said annular recess and hence the piston 62 is inserted smoothly into the cylinder bore 13. Particularly in the case where the piston 62 is provided with the piston ring 75 as in the previous modification, there is no fear that the piston ring 75, which can behave independently of the piston 62, may drop into the annular recess. In this case, a particularly outstanding effect can thus be obtained.

The following description is now provided about <sup>eighth</sup> an embodiment <sup>will now be</sup> (the eighth embodiment) of the invention described in the foregoing <sup>with reference to</sup> eleventh, twelfth and fourteenth aspects, which is illustrated in Figs. 12 and 13.

Fig. 12 is an explanatory diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the eighth embodiment and Fig. 13 is a diagram showing a

series of operations of the work chucking/inserting apparatus in a successive manner

<sup>apparatus 60</sup>  
In the work chucking/inserting <sup>apparatus 60</sup> structure of this eighth embodiment, indicated at 60, the structures of the work chucking/inserting apparatuses 60 described in the first, sixth and seventh embodiments are united <sup>and</sup> the inner surfaces of the chuck fingers are also tapered <sup>inward</sup> so that the closer to their tips, ~~the more inwards the taper, and this taper structure is combined~~ with the united structure.

In the work chucking/inserting apparatus 60 of this eighth embodiment, in comparison with the first embodiment, as shown in Figs. 12 and 13, there is further provided a pushing mechanism 72 for pushing the piston (work) 62 toward the cylinder bore (insertion hole) 3, and the inner surfaces of the chuck fingers 65 <sup>used</sup> respectively have tapered portions 78 which <sup>are</sup> tapered <sup>inward</sup> so that the closer to the tips ~~the more inwards the taper,~~ and serve as chuck surfaces for chucking the piston 62. Further, the inlet of the cylinder bore 13 is chamfered at 76 and the tips (extremities) ~~of the tip~~ <sup>end portions</sup> of the outer surfaces of the chuck fingers 65 are formed so that they can <sup>be</sup> abutted against the chamfered portion 76 without leaving any gap when the piston 62 is inserted into the cylinder bore 13 (see Fig. 13g and 13h). <sup>Otherwise,</sup>

<sup>the same as</sup>  
[In the above points] the eighth embodiment is <sup>different from</sup> the first embodiment, ~~but there is nothing else different from the first~~ <sup>further</sup> embodiment, so a detailed explanation thereof will be omitted.

<sup>now</sup>  
~~Next, the~~ Operation of the eighth embodiment will <sup>now</sup> be described [below] with reference, as an example, to the case where the work chucking/inserting apparatus 60 is used in a vertically installed state.

In this eighth embodiment, when the work chucking/inserting

apparatus 60 detects the position of the cylinder bore 13, the inner surfaces of the chuck fingers 65 have already chucked the piston 62.

The work chucking/inserting apparatus 60 with the piston 62 thus already chucked by the chuck fingers 65 is first advanced (<sup>lowered</sup> ~~brought down~~), allowing the tapered tip end portions of the outer surfaces of the chuck fingers 65 to come into contact with one side of the chamfered portion 76 of the inlet of the cylinder bore 13, as shown in Fig. 13a. Next, the work chucking/inserting apparatus 60 is further advanced, allowing the tip end portions of the outer surfaces of the chuck fingers 65 to follow the chamfered portion 76. At the same time, the base portion 64, together with the chuck fingers 65, is moved gradually to the right in Fig. 13 by operation of the <sup>serving</sup> floating mechanism 69 as a tracer mechanism (Figs. 13b-d). When the work chucking/inserting apparatus 60 has <sup>been inserted to an extent where it cannot</sup> ~~come to be unable to~~ further advance, the tip end portions of the outer surfaces of all the six chuck fingers 65 are in contact with the chamfered portion 76, without ~~leaving~~ <sup>therebetween,</sup> any gap and the <sup>ion of</sup> ~~work for~~ detecting the position of the cylinder bore 13 (horizontal positioning of the work chucking/inserting apparatus 60) is completed (Fig. 13d).

Next, the work chucking/inserting apparatus 60 is <sup>retracted</sup> ~~retreated~~ (raised) to the position <sup>at</sup> ~~to~~ which the tips of the chuck fingers 65 have advanced into the cylinder bore 13 by a distance corresponding to <sup>the</sup> a vertical length (in the axial direction of the cylinder bore 13) of the chamfered portion 76, to complete a vertical positioning of the work chucking/inserting apparatus 60 (Fig. 13e). Then, the plunger of the pushing mechanism 72 is extended to push the piston 62, allowing the piston to slide on the tapered portions 78 of the inner surfaces of the chuck fingers 65. As a result, the tip end portions of the outer surfaces of the chuck fingers 65 are gradually

expanded radially outwards (Figs. 13f-h), permitting the piston 62 to pass through the expanded passage (piston insertion path). Thus, the piston 62 can be inserted into the cylinder bore 13 positively and smoothly while being guided by the tapered portions 78 without disengagement ~~or drop~~ from the chuck fingers 65. At this time, the tips of the outer surfaces of the chuck fingers 65 ~~are in~~ <sup>there between</sup> abutment with the chamfered portion 76 without leaving any gap.

Since this eighth embodiment is constructed and operates as above, the work chucking/inserting apparatus 60 need not <sup>move to the temporary rest 40</sup> go to the feed place of the piston 62 to fetch <sup>2</sup> the piston 62, and the work for detecting the position of the cylinder bore 13 can be done while the piston 62 is kept chucked by the inner surfaces of the chuck fingers 65. Therefore, the piston 62 can be inserted into ~~and~~ aligned with the cylinder bore 13 in a ~~still~~ shorter time and <sup>with 2</sup> in a still higher working efficiency. Thus, it is possible to make contribution <sup>65</sup> to the improvement of productivity in an engine assembly line. Besides, <sup>without</sup> even if there are not provided any special hole position detecting fingers (see the third embodiment) separately from the chuck fingers 65 for chucking the piston 62, it is not necessary for the work chucking/inserting apparatus to go to the piston feed place to fetch the piston 62, <sup>thereby simplifying</sup> [In other words,] the structure of the work chucking/inserting apparatus 60 does not become complicated.

Further, since the mechanical floating mechanism 69 is used as the tracer mechanism, the work chucking/inserting apparatus 60 is simple in structure and low in cost, not using any complicated force control. In addition, there can be attained the same effects as in the first, sixth and seventh embodiments.

~~Next, a description will be given below about an embodiment (the~~

<sup>will now be</sup>  
A ninth embodiment of the invention described in the foregoing thirteenth <sup>with reference to</sup> aspect, which is illustrated in Figs. 14 and 15.

Fig. 14 is a diagram showing, in a modeled form, the structure of a principal portion of a work chucking/inserting apparatus according to the ninth embodiment and Fig. 15 is a diagram showing a series of operations of the work chucking/inserting apparatus in a successive manner.

The work chucking/inserting apparatus <sup>60</sup> of this ninth embodiment, indicated at 60, is different from that of the previous eighth embodiment in the shape of outer surfaces of chuck fingers 65 which function, <sup>to</sup> not only to detect the position of the insertion hole, but also effect positioning of the work chucking/inserting apparatus 60. More specifically, in the eighth embodiment, <sup>25 in</sup> like the first embodiment, the outer surfaces of the chuck fingers 65 are tapered at least at their tip end portions, <sup>inward</sup> in such a manner <sup>toward</sup> that the closer to their tips, the more inwards the taper, and can contact the inlet of the cylinder bore 13. <sup>However,</sup> <sup>505</sup> <sup>with</sup> in this ninth embodiment, end faces of the chuck fingers 65 are formed flat <sup>at their portions</sup> ("flat portions" hereinafter) exclusive of their inner edges and the vicinities thereof, <sup>for</sup> and can <sup>come into</sup> abutment against the wall surface which surrounds the inlet of the cylinder bore 13, and the inner peripheral edges and the vicinities thereof are tapered <sup>inwardly toward</sup> at 80 so that the closer to the tips, the more inwards the <sup>for</sup> taper, and can contact the inlet of the cylinder bore 13. Further, the outer surfaces of the chuck fingers 65 are generally arcuate and perpendicularly <sup>with</sup> contiguous to the end faces of the chuck fingers, not being particularly <sup>involved</sup> concerned in the detection of the insertion hole position or positioning of the work chucking/inserting apparatus 60.

~~In this~~ In the ninth embodiment, the inner peripheral edges of the end faces of the chuck fingers 65 and the vicinities thereof are formed so that

they can be put in abutment against the chamfered portion 76 without leaving any gap upon insertion of the piston 62 into the cylinder bore 13 (see Figs. 15f and 15g) and so that the axis of a conical surface defined by the inner peripheral edges and the vicinities thereof of the end faces of all the six chuck fingers 65 is aligned with the axis of the cylinder bore 13 when those inner peripheral edges and the vicinities thereof come into contact with the inlet of the cylinder bore 13. *Other than the foregoing features,*

~~In the above points~~ the ninth embodiment is <sup>so</sup> different from the previous eighth embodiment, ~~but there is nothing else different from the~~ eighth embodiment, <sup>further</sup> so a detailed explanation thereof will be omitted.

The operation of the ninth embodiment will <sup>now</sup> be described below with reference, as an example, to the case where the work chucking/inserting apparatus 60 is used <sup>oriented</sup> in a vertically installed state.

The function of the ninth embodiment is different from that of the eighth embodiment in the sequence <sup>of operations</sup> and concrete mode of <sup>in the</sup> both operations <sup>of</sup> one of which is detecting the position of the insertion hole by the work chucking/inserting apparatus 60 (horizontal positioning of the work chucking/inserting apparatus 60) and <sup>is</sup> the other of which is <sup>of</sup> positioning the work chucking/inserting apparatus 60 at the time of insertion of the work into the insertion hole (vertical positioning of the work chucking/inserting apparatus 60).

In connection with the sequence of both operations, in the previous eighth embodiment there is first performed the operation of <sup>the</sup> detecting the position of the cylinder bore 13 by the work chucking/inserting apparatus 60 (horizontal positioning of the work chucking/inserting apparatus 60) <sup>occurs first,</sup> and <sup>followed by</sup> there is next performed the operation of positioning the work chucking/inserting apparatus 60 at the time of insertion of the piston 62.

into the cylinder bore 13 (vertical positioning of the work chucking/inserting apparatus 60), whereas this sequence is reversed in this ninth embodiment.

In the ninth embodiment, as shown in Fig. 15a, the work chucking/inserting apparatus 60 with the piston 62 already chucked by the chuck fingers 65 is first advanced (~~brought down~~ <sup>lowered to bring</sup>), allowing flat portions 79 of end faces of the chuck fingers 65 [to come] into abutment against the wall surface which surrounds the inlet of the cylinder bore 13, whereby the vertical positioning of the work chucking/inserting apparatus 60 is completed (Fig. 15b). Next, the plunger of the pushing mechanism 72 is extended to push the piston 62, allowing the piston 62 to slide on the tapered portions 78 of the inner surfaces of the chuck fingers 65, whereby the tips of the chuck fingers 65 (the tapered portions 80 of the inner peripheral edges of the end faces and the vicinities thereof) are gradually expanded radially outwards <sup>to an</sup> [in] equal <sup>extent</sup> [quantities] for all of the six chuck fingers 65, allowing the tips of the chuck fingers 65 to follow the chamfered portion 76. At the same time, the base portion 64, together with the chuck fingers 65, is gradually moved rightwards in Fig. 15 by operation of the floating mechanism 69 <sup>serving</sup> as the <sup>tracer</sup> mechanism (Figs. 15c-e).

In this way it becomes possible for the piston 62 to pass through an expanded passage (piston insertion path) which results <sup>when</sup> [from] the tips of the chuck fingers 65 <sup>are moved</sup> [being expanded] radially outwards, and the tapered portions 80 of the inner peripheral edges and the vicinities thereof of the end faces of all the six chuck fingers 65 come into contact with the chamfered portion 76 to complete the operation <sup>of</sup> [for] detecting the position of the cylinder bore 13 (horizontal positioning of the work chucking/inserting apparatus 60) (Fig. 15e).

Next, the plunger of the pushing mechanism 72 is further extended

to push the piston 62, whereby the piston 62 can be inserted into the cylinder bore 13 without disengagement or drop from the chuck fingers 65. At this time, the tapered portions 80 of the end face inner peripheral edges and the vicinities thereof of the chuck fingers 65 are in abutment against the chamfered portion 76 without leaving any gap.

With the Since this ninth embodiment is constructed and operates as above, when the work chucking/inserting apparatus 60 detects the position of the cylinder bore 13, the flat end face portions 79 of the chuck fingers 65 can be allowed to serve as surfaces for positioning the work chucking/inserting apparatus 60 in the axial direction of the cylinder bore 13, and the apparatus 60 can be brought into a standstill in that direction, with elimination of an axial deflection. These points <sup>features</sup> combine to improve the accuracy of detecting the position of the cylinder bore 13. <sup>Moreover</sup> Besides, the detection of the positions of the cylinder bore 13 and the insertion of the piston 62 into the cylinder bore 13 can be done simultaneously. Consequently, the piston 62 can be inserted into and aligned with the cylinder bore 13 in a still <sup>with a yet</sup> shorter time and in a still <sup>with a yet</sup> higher working efficiency. In addition, there can be attained the same effects as in the first, sixth, seventh and eighth embodiments.

Next, reference will be made below to an embodiment <sup>A</sup> (the tenth embodiment) <sup>will now be</sup> of the invention described in the foregoing fifteenth aspect, <sup>with</sup> which is illustrated in Fig. 16.

~~Fig. 16 is a diagram showing, in a successive manner, a series of operations of a work chucking/inserting apparatus according to this tenth embodiment.~~

The work chucking/inserting apparatus <sup>60</sup> of <sup>the</sup> this tenth embodiment indicated at 60, is different from the previous <sup>described</sup> eighth and ninth

embodiments in that it uses a pushing mechanism 72 possessing a <sup>holding</sup> ~~sucking~~ <sup>vacuum chucking</sup> function for the work (piston 62). To be more specific, a plunger which constitutes the pushing mechanism 72 is formed with a through hole communicating with a vacuum source, though not shown in detail.

Since the tenth embodiment is constructed as above, the operation thereof is different as follows from the previous eighth and ninth embodiments.

~~A description will now be given with the eighth embodiment as a~~  
<sup>By way of comparison,</sup> ~~comparative example.~~ In the operations of the eighth embodiment

illustrated in Figs. 13f, et seq., the plunger of the pushing mechanism 72 is extended to push the piston 62, <sup>and</sup> the piston 62 ~~is~~ <sup>is</sup> allowed to ~~slide~~ <sup>slide</sup> on the tapered portions 78 of the inner surfaces of the chuck fingers 65, thereby gradually expanding the tips of the chuck fingers 65 radially outwards to permit the piston 62 to pass through the thus-expanded passage (piston insertion path) into the cylinder bore 13 without disengagement ~~or drop~~ from the chuck fingers 65. On the other hand, in this tenth embodiment, the radially outward expansion of the tips of the chuck fingers 65 is performed by operation of a base portion 64 which holds the chuck fingers 65 in a <sup>for radial extension and retraction</sup> ~~radially~~ <sup>advancable and retreatable</sup> manner.

<sup>In the tenth embodiment,</sup> ~~When~~ the tip ends of the chuck fingers 65 are expanded radially outwards by operation of the base portion 64, the piston 62 is released from the chuck fingers 65, but is not disengaged ~~nor drops~~ <sup>nor drops</sup> from the work chucking/inserting apparatus 60 because the piston 62 is <sup>vacuum chucked</sup> ~~sucked~~ by the plunger of the pushing mechanism 72 (Fig. 16f). When ~~a~~ continued operation of the base portion 64 has expanded the tips of the chuck fingers 65 radially outwards <sup>into</sup> ~~until~~ abutment against the chamfered portion 76, the plunger of the pushing mechanism 72 is extended to push the piston 62

gradually, whereby the piston 62 can be inserted into the cylinder bore 13 (Figs. 16f-h). In this case, the degree of expansion of the tips of the chuck fingers 65 caused by operation of the base portion 64 is preferably adjusted so that the piston 62 is allowed to slide only the last slight distance on the tapered portions 78 of the inner surfaces of the chuck fingers 65, whereby the tapered portions 78 can be allowed to serve as a guide for insertion of the piston 62 into the cylinder bore 13.

~~A description will now be given with the ninth embodiment as a~~  
~~comparative example.~~ In ~~the operations of~~ the ninth embodiment illustrated in Figs. 15c et seq., the plunger of the pushing mechanism 72 is extended to push the piston 62, allowing the piston 62 to slide on the tapered portions 78 of the inner surfaces of the chuck fingers 65, thereby gradually expanding the tips of the chuck fingers 65 (the tapered portions 80 of the inner peripheral edges of end faces and the vicinities thereof) radially outwards so as to permit the piston 62 to pass through the thus-expanded passage (piston insertion path), and the position of the cylinder bore 13 is detected, whereby the piston 62 can be inserted into the cylinder bore 13 without disengagement ~~or drop~~ from the chuck fingers 65. ~~On the~~ <sup>In contrast</sup>  
~~other hand,~~ in this tenth embodiment, the radially outward expansion of the tips of the chuck fingers 65 is effected by operation of a base portion 64 which holds the chuck fingers 65 ~~in a radially advanceable and retreatable~~  
~~manner.~~

The operation of the base portion 64 and that of the pushing mechanism 72, as well as the mode of insertion of the piston 62 into the cylinder bore 13 based on those operations, should be fully understood from the above descriptions, so a detailed description thereof will here be omitted.

<sup>with</sup> Since the tenth embodiment ~~is constructed and operates as above,~~

even if the inner surfaces of the chuck fingers 65 have already chucked the piston 62 before the work chucking/inserting apparatus 60 detects the position of the cylinder bore 13, there is no fear of the piston 62 being disengaged or dropping from the work chucking/inserting apparatus 60 when the tips of the chuck fingers 65 are expanded radially outwards for passage of the piston 62 or for detecting the position of the cylinder bore 13, because the piston 62 is <sup>vacuum chucked</sup> sucked by the plunger of the pushing mechanism 72, thus permitting the piston 62 to be inserted positively into the cylinder bore 13. <sup>Moreover</sup> Besides, there is no fear of damage to the piston 62 because the piston 62 <sup>undergoes only</sup> is little pushed by the pushing mechanism 72 for sliding on the tapered inner surface portions 78 of the chuck fingers 65.

Although in all of the above first to tenth embodiments the number of the piston chuck fingers 65 is six, <sup>the invention is not so limited, i.e.</sup> there is made no limitation thereto <sup>may be</sup> [insofar as] there are three or more such fingers. Particularly, the minimum number will <sup>suffice</sup> [do] if the hole position detecting fingers 71 are, provided separately. Even two <sup>such fingers</sup> will do if a wide chuck surface can be <sup>provided</sup> ensured.

Further, although in the above first to seventh embodiments the piston 62 is inserted horizontally into the cylinder bore 13, this constitutes no limitation. The piston may be inserted into the cylinder bore vertically from above. Various other changes and modifications may be made <sup>without</sup> [within] the scope not departing from the gist of the present invention.

# ABSTRACT

A work chucking/inserting <sup>device</sup> [apparatus 60 to be used] for chucking [a] work (piston 62) and inserting <sup>2</sup> [the] work into an insertion hole (cylinder bore) in alignment with the hole, including <sup>es</sup> three or more chuck fingers [65], the chuck fingers [65] being arranged in circumferentially spaced positions and <sup>mounted for</sup> capable of <sup>retracting</sup> advancing and <sup>retracting</sup> retreating radially, inner surfaces of the chuck fingers [65] <sup>e</sup> serving as chuck surfaces for chucking the work, and outer surfaces of the chuck fingers [65] <sup>are</sup> being tapered at least at tip end portions thereof so that the closer <sup>radially inward toward</sup> to the tips, ~~the more inwards the taper, and~~ <sup>for</sup> capable of coming into contact with an inlet of the insertion hole. The work chucking/inserting <sup>device</sup> [apparatus 60] further includes a tracer mechanism which causes the axis of a conical surface defined by the outer surfaces of the chuck fingers [65] to be <sup>come</sup> aligned with the axis of the insertion hole when the outer surfaces of the chuck fingers [65] are put in contact <sup>is included</sup> with the inlet of the insertion hole. <sup>is included</sup> A pushing mechanism for pushing the work toward the insertion hole. The work chucking/inserting <sup>device</sup> [apparatus] can handle <sup>pieces</sup> various sizes of work <sup>device</sup> with a simple structure, <sup>with</sup> and that <sup>with</sup> in a short time and <sup>with</sup> [a] high working efficiency.